

THE CLAIMS DEFINING THE INVENTION ARE AS FOLLOWS:

1. A method of creating a depth map including the steps of:  
 assigning a depth to at least one pixel or portion of an image;  
 determining relative location and image characteristics for each said at least one pixel or portion of said image;  
 utilising said depth(s), image characteristics and respective relative location to determine a configuration of a first algorithm to ascertain depth characteristics as a function of relative location and image characteristics;  
 utilising said first algorithm to calculate a depth characteristic for each pixel or portion of said image;  
 wherein said depth characteristics form a depth map for said image.
2. A method as claimed in claim 1, wherein said image characteristics include RGB values.
3. A method as claimed in claim 1 further including the step of reassigning a depth to any pixel or portion of said image to correct for any inconsistencies.
4. A method as claimed in claim 1, wherein said image characteristics include at least one of luminance, chrominance, contrast or spatial measurements.
5. A method as claimed in claim 1, wherein said first algorithm may be represented by the equation:  

$$z = f(x, y, R, G, B)$$
 where x and y define the relative location of a sample.
6. A method as claimed in claim 1, wherein a learning algorithm is utilised to determine the configuration of said first algorithm.
7. A method as claimed in claim 6, wherein for each pixel in the image, the learning algorithm computes:  

$$z_n = k_a \cdot x_n + k_b \cdot y_n + k_c \cdot R_n + k_d \cdot G_n + k_e \cdot B_n$$

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where

$n$  is the  $n$ th pixel in the key-frame image

$z_n$  is the value of the depth assigned to the pixel at  $x_n, y_n$

$k_a$  to  $k_g$  are constants and are determined by the algorithm

$R_n$  is the value of the Red component of the pixel at  $x_n, y_n$

$G_n$  is the value of the Green component of the pixel at  $x_n, y_n$

$B_n$  is the value of the Blue component of the pixel at  $x_n, y_n$

8. A method as claimed in claim 6, wherein a random component is introduced to the learning algorithm to reduce over-training.
9. A method as claimed in claim 8, wherein said random component is a small positive or negative random number.
10. A method as claimed in claim 7, wherein said learning algorithm initially identifies pixels having similar characteristics to a known pixel.
11. A method as claimed in claim 10, wherein similar pixels are searched for within a search radius.
12. A method as claimed in claim 11, wherein said search radius varies for each characteristic.
13. A method as claimed claim 11, wherein the depth of a pixel is determined by a weighted average of distances from similar pixels.
14. A method as claimed in claim 13, wherein weights are inversely proportioned to distance.
15. A method as claimed in claim 6, wherein each characteristic is divided or partitioned into a set of regions and a depth value assigned based on the region which is occupied.

**SECRET**

16. A method of creating a depth map including the steps of:  
assigning a depth to at least one pixel or portion of an image;  
determining x,y coordinates and image characteristics for each said at least one pixel or portion of said image;  
utilising said depth(s), image characteristics and respective x,y coordinates to determine a first algorithm to ascertain depth characteristics as a function of x,y coordinates and image characteristics;  
utilising said first algorithm to calculate a depth characteristic for each pixel or portion of said image;  
wherein said depth characteristics form a depth map for said image.
17. A method as claimed in claim 16, wherein said image characteristics include RGB values.
18. A method as claimed in claim 16 further including the step of reassigning a depth to any pixel or portion of said image to correct for any inconsistencies.
19. A method as claimed in claim 16, wherein said image characteristics include at least one of luminance, chrominance, contrast or spatial measurements.
20. A method as claimed in claim 16, wherein said first algorithm may be represented by the equation:
$$z = f(x,y,R,G,B)$$
where x and y define the relative location of a sample.
21. A method as claimed in claim 16, wherein a learning algorithm is utilised to determine the configuration of said first algorithm.
22. A method as claimed in claim 21, wherein for each pixel in the image, the learning algorithm computes:
$$Z_n = k_a \cdot x_n + k_b \cdot y_n + k_c \cdot R_n + k_d \cdot G_n + k_e \cdot B_n$$
where

where

$n$  is the  $n$ th pixel in the key-frame image

$z_n$  is the value of the depth assigned to the pixel at  $x_n, y_n$

$k_a$  to  $k_e$  are constants and are determined by the algorithm

$R_n$  is the value of the Red component of the pixel at  $x_n, y_n$

$G_n$  is the value of the Green component of the pixel at  $x_n, y_n$

$B_n$  is the value of the Blue component of the pixel at  $x_n, y_n$

23. A method as claimed in claim 21, wherein a random component is introduced to the learning algorithm to reduce over-training.
24. A method as claimed in claim 23, wherein said random component is a small positive or negative random number.
25. A method as claimed in claim 21, wherein said learning algorithm initially identifies pixels having similar characteristics to a known pixel.
26. A method as claimed in claim 25, wherein similar pixels are searched for within a search radius.
27. A method as claimed in claim 26, wherein said search radius varies for each characteristic.
28. A method as claimed in of claim 25, wherein the depth of a pixel is determined by a weighted average of distances from similar pixels.
29. A method as claimed in claim 28, wherein weights are inversely proportioned to distance.
30. A method as claimed in claim 21, wherein each characteristic is divided or partitioned into a set of regions and a depth value assigned based on the region which is occupied.

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31. A method of creating a series of depth maps for an image sequence including the steps of:
- receiving a depth map for at least one frame of said image sequence;
  - utilising said at least one depth map to determine a second configuration of a second algorithm to ascertain the depth characteristics as a function of relative location and image characteristics;
  - utilising said algorithm to create a depth map for each frame of said image sequence.
32. A method as claimed in claim 31, wherein at least two depth maps corresponding to at least two frames of said image sequence are received.
33. A method as claimed in claim 31, wherein said image characteristics include RGB values.
34. A method as claimed in claim 31, wherein said image characteristics include at least one of luminance, chrominance, contrast or spatial measurements.
35. A method as claimed in claim 31, wherein a learning algorithm is utilised to determine the configuration of said second algorithm.
36. A method as claimed in claim 35, wherein said learning algorithm is one of back propagation algorithm, C4.5 algorithm, or K-means algorithm.
37. A method as claimed in claim 35, wherein said second algorithm computes:

$$Z_n = k_a \cdot x_n + k_b \cdot y_n + k_c \cdot R_n + k_d \cdot G_n + k_e \cdot B_n$$

where

$n$  is the  $n$ th pixel in the key-frame image

$z_n$  is the value of the depth assigned to the pixel at  $x_n, y_n$

$k_a$  to  $k_e$  are constants and are determined by the algorithm

$R_n$  is the value of the Red component of the pixel at  $x_n, y_n$

$G_n$  is the value of the Green component of the pixel at  $x_n, y_n$

$B_n$  is the value of the Blue component of the pixel at  $x_n, y_n$

38. A method as claimed in claim 31, wherein additional algorithm configurations are created for each pair of frames for which depth maps have been received.
39. A method of creating a series of depth maps for an image sequence including the steps of:
- receiving a depth map for at least one frame of said image sequence;
  - utilising said at least one depth map to determine a second algorithm to ascertain the depth characteristics as a function of  $x, y$  coordinates and image characteristics;
  - utilising said algorithm to create a depth map for each frame of said image sequence.
40. A method as claimed in claim 39, wherein at least two depth maps corresponding to at least two frames of said image sequence are received.
41. A method as claimed in claim 39, wherein said image characteristics include RGB values.
42. A method as claimed in claim 39, wherein said image characteristics include at least one of luminance, chrominance, contrast or spatial measurements.
43. A method as claimed in claim 39, wherein a learning algorithm is utilised to determine the configuration of said second algorithm.
44. A method as claimed in claim 43, wherein said learning algorithm is one of back propagation algorithm, C4.5 algorithm, or K-means algorithm.

45. A method as claimed in claim 43, wherein said second algorithm computes:

$$Z_n = k_a \cdot x_n + k_b \cdot y_n + k_c \cdot R_n + k_d \cdot G_n + k_e \cdot B_n$$

where

$n$  is the  $n$ th pixel in the key-frame image

$z_n$  is the value of the depth assigned to the pixel at  $x_n, y_n$

$k_a$  to  $k_s$  are constants and are determined by the algorithm

$R_n$  is the value of the Red component of the pixel at  $x_n, y_n$

$G_n$  is the value of the Green component of the pixel at  $x_n, y_n$

$B_n$  is the value of the Blue component of the pixel at  $x_n, y_n$

46. A method as claimed in claim 39, wherein additional algorithm configurations are created for each pair of adjacent frames for which depth maps have been received.

47. A method of creating a series of depth maps for an image sequence including the steps of;

receiving depth maps for at least two key frames of said image sequence;  
utilising said depth maps to generate a 3D model of said scene;

utilising said depth maps to determine a second algorithm to ascertain the characteristics of a function.

utilising said algorithm to create a depth map of each frame of said image sequence, wherein frames adjacent said key frames are processed prior to non-adjacent frames.

48. A method as claimed in claim 47, wherein once said adjacent key frame is processed, said adjacent key frame is then considered a key frame for creation of further depth maps.

49. A method as claimed in claim 35, 43, or 47, wherein said second algorithm computes:

$$Z_n = k_a \cdot x_n + k_b \cdot y_n + k_c \cdot R_n + k_d \cdot G_n + k_e \cdot B_n + k_f \cdot T$$

where:

$n$  is the  $n$ th pixel in the image





53. A method of encoding a series of frames including transmitting at least one mapping function together with said frames, wherein said mapping function includes an algorithm to ascertain depth characteristics as a function of relative location and image characteristics.

54. A method as claim in claim 53, wherein said image characteristics include RGB values.

55. A method as claimed in claim 53, wherein said image characteristics include at least one of luminance, chrominance, contrast or spatial measurements.

56. A method as claimed in claim 53, wherein a learning algorithm is utilised to determine said mapping function.

57. A method as claimed in claim 56, wherein said learning algorithm is one of back propagation algorithm, C4.5 algorithm, or K-means algorithm.

58. A method as claimed in claim 56, wherein said mapping function computes:

$$Z_n = k_a \cdot X_n + k_b \cdot Y_n + k_c \cdot R_n + k_d \cdot G_n + k_e \cdot B_n$$

where

$n$  is the  $n$ th pixel in the key-frame image

$Z_n$  is the value of the depth assigned to the pixel at  $x_n, y_n$

$k_a$  to  $k_e$  are constants and are determined by the algorithm

$R_n$  is the value of the Red component of the pixel at  $x_n, y_n$

$G_n$  is the value of the Green component of the pixel at  $x_n, y_n$

$B_n$  is the value of the Blue component of the pixel at  $x_n, y_n$

59. A method as claimed in claim 53, wherein additional algorithms are created for each pair of frames for which depth maps have been received.

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